

IN THE CLAIMS:

1. **(Currently Amended)** Automatically controlled multi-axis manipulator for a processing tool, ~~(11), with~~ comprising at least ~~[[two]]~~ a first and a second, in particular, hollow component members ~~[[1,4,5,6]]~~, wherein ~~[[the]]~~ said first member ~~[[6]]~~, on which ~~[[the]]~~ said processing tool ~~[[11]]~~ to be moved by ~~[[the]]~~ said manipulator is arranged, can be turned relative to ~~[[the]]~~ said second member ~~[[1,4,5]]~~, and with a line arrangement ~~(20,21)~~ that leads to ~~[[the]]~~ said processing tool ~~[[11]]~~ on or through the component members ~~[[1,4,5,6]]~~ and is fixed on a part ~~(13,33)~~ of ~~[[the]]~~ said processing tool, ~~(11), characterized by the fact that the~~ wherein said part ~~(13,33)~~ of ~~[[the]]~~ said processing tool ~~[[11]]~~ on which ~~[[the]]~~ said line arrangement ~~(20,21)~~ is fixed is supported in a rotatable fashion relative to ~~[[the]]~~ said first component member ~~[[6]]~~.

2. **(Currently Amended)** Manipulator The manipulator according to Claim 1, ~~characterized by the fact that the~~ wherein said part ~~(13,33)~~ of ~~[[the]]~~ said processing tool ~~[[11]]~~ on which ~~[[the]]~~ said line arrangement ~~(20,21)~~ is fixed is rotatably supported in an outer housing ~~(12,32)~~ that is rigidly connected to ~~[[the]]~~ said first component member ~~[[6]]~~.

3. **(Currently Amended)** Manipulator The manipulator according to Claim 1, ~~or 2,~~ ~~characterized by the fact that the~~ wherein said line arrangement ~~(20,21)~~ leading to processing tool ~~[[11]]~~ contains supply hoses for at least one of liquid, ~~and/or~~ gaseous media, and~~[[/or]]~~ signal lines.

4. **(Currently Amended)** Manipulator The manipulator according to ~~one of the preceding claims, characterized by the fact that~~ Claim 1, comprising a flexible shaft for absorbing torque leads through ~~[[the]]~~ said component members ~~[[1,4,5,6]]~~ parallel to ~~[[the]]~~ said line arrangement ~~(20,21)~~ and ~~[[is]]~~ fixed on ~~[[the]]~~ said rotatably supported part ~~(13,33)~~ of ~~[[the]]~~ said processing tool ~~[[11]]~~.

5. (Currently Amended) Manipulator The manipulator according to ~~one of the preceding claims~~ Claim 2, characterized by the fact that wherein said component members ~~[[4, 5, 6] which]]~~ form ~~[[the]]~~ a wrist joint ~~[[2]]~~ of a robot ~~are provided~~.

6. (Currently Amended) Manipulator The manipulator according to ~~one of the preceding claims, characterized by the fact that~~ Claim 5, wherein said processing tool ~~[[41]]~~ consists of an atomizer or another application device that is moved by a ~~spray painting~~ said robot, wherein the and said interior part ~~(13, 33)~~ of ~~[[the]]~~ said processing tool ~~[[41]]~~ which is connected to ~~[[the]]~~ said line arrangement ~~(20, 21)~~ is rotatably supported in ~~[[the]]~~ said outer housing ~~(12, 32)~~ of ~~[[the]]~~ said atomizer or the like which is rigidly connected to ~~[[the]]~~ said wrist joint ~~[[2]]~~ of ~~[[the]]~~ said robot.

7. (Currently Amended) Manipulator The manipulator according to ~~one of the preceding claims, characterized by the fact that~~ Claim 6, comprising an annular ring ~~[[gap (27) or ring channel (45, 46)]]~~ for a medium to be conveyed through the processing tool is formed between the outer side of ~~[[the]]~~ said interior part ~~(13, 33)~~ of ~~[[the]]~~ said processing tool ~~[[41]]~~ which is connected to ~~[[the]]~~ said line arrangement ~~(20, 21)~~ and its outer housing ~~(12, 32)~~ that is rigidly connected to the first component member ~~[[6]]~~, wherein said ring ~~gap or ring channel~~ is limited by sliding seals ~~[[28, 29, 47]]~~ that are seated between the inner side of ~~[[the]]~~ said outer housing ~~(12, 32)~~ and the outer side of ~~[[the]]~~ said interior part ~~(13, 33)~~ and adjoin ~~[[the]]~~ said housing ~~(12, 32)~~ and ~~[[the]]~~ said interior part ~~(13, 33)~~.

8. (Currently Amended) Manipulator The manipulator according to ~~one of the preceding claims, characterized by the fact that~~ Claim 7, comprising a sealed rotary leadthrough ~~[[58, 47, 47', 59]]~~ provided within ~~[[the]]~~ said processing tool for at least one line for a medium ~~(F, ZL, HL)~~ to be conveyed outwardly through ~~[[the]]~~ said processing tool, wherein ~~[[the]]~~ said medium is conveyed through at least one of a central channel ~~[[40', 56]]~~ that extends along a

central axis of ~~[[the]]~~ said processing tool ~~[[or]]~~ and through a ring channel ~~[(27, 45, 46, 45', 46')]]~~.

9. (Currently Amended) ~~Manipulator~~ The manipulator according to Claim 8, ~~characterized by the fact that~~ comprising at least one additional rotary leadthrough ~~[[is]]~~ provided for at least one line ~~[(41, 41')]]~~ that terminates in the processing tool.

10. (Currently Amended) ~~Manipulator~~ The manipulator according to ~~one of the preceding claims~~ Claim 9, ~~characterized by the fact that the~~ wherein said processing tool ~~e.g., an atomizer for coating material,~~ is supported on a mechanical interface of ~~[[the]]~~ said ~~manipulator, e.g., on the end member of the~~ wrist joint of a robot, ~~such that it~~ and is rotatable in its entirety relative to this interface.